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(54) **ROUND-ROBIN SENSING DEVICE AND METHOD OF USE**

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(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 419 days.

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(57) **ABSTRACT**

Related U.S. Application Data

A round-robin sensing device is disclosed. The round-robin sensing device comprises a MEMS device, wherein the MEMS device includes first and second sense electrodes. The round-robin sensing device also comprises a multiplexer coupled to the first and second sense electrodes, at least one sense amplifier coupled to the multiplexer, a demodulator coupled to the at least one sense amplifier, and an integrate and dump circuit coupled to the demodulator. Finally, the round-robin sensing device comprises an analog-to-digital converter (ADC) coupled to the de-multiplexer, wherein the multiplexer, the at least one sense amplifier and the demodulator provide a continuous time sense path during amplification that is resettable and wherein the integrate and dump circuit and the ADC provide a discrete time processing path.

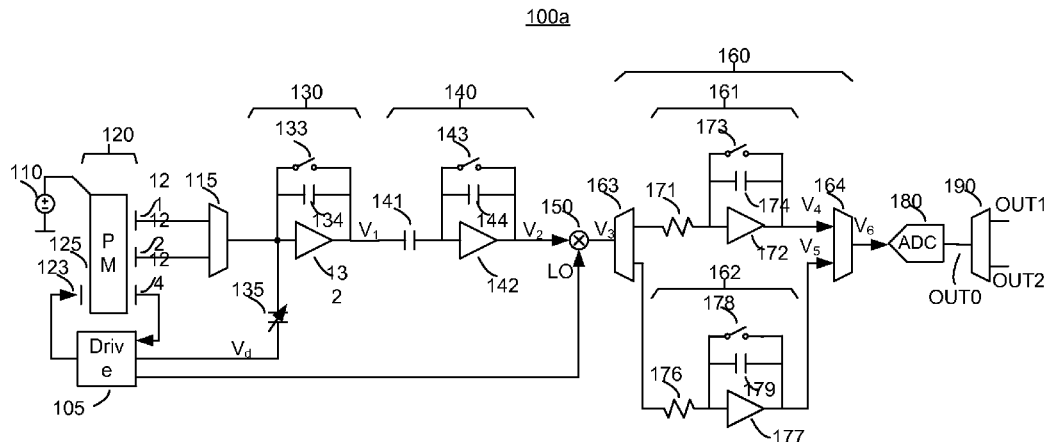
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CPC **G01P 1/04** (2013.01); **G01C 19/5776** (2013.01)

(58) **Field of Classification Search**
USPC 73/504.02, 528; 324/658; 702/151
See application file for complete search history.

21 Claims, 5 Drawing Sheets



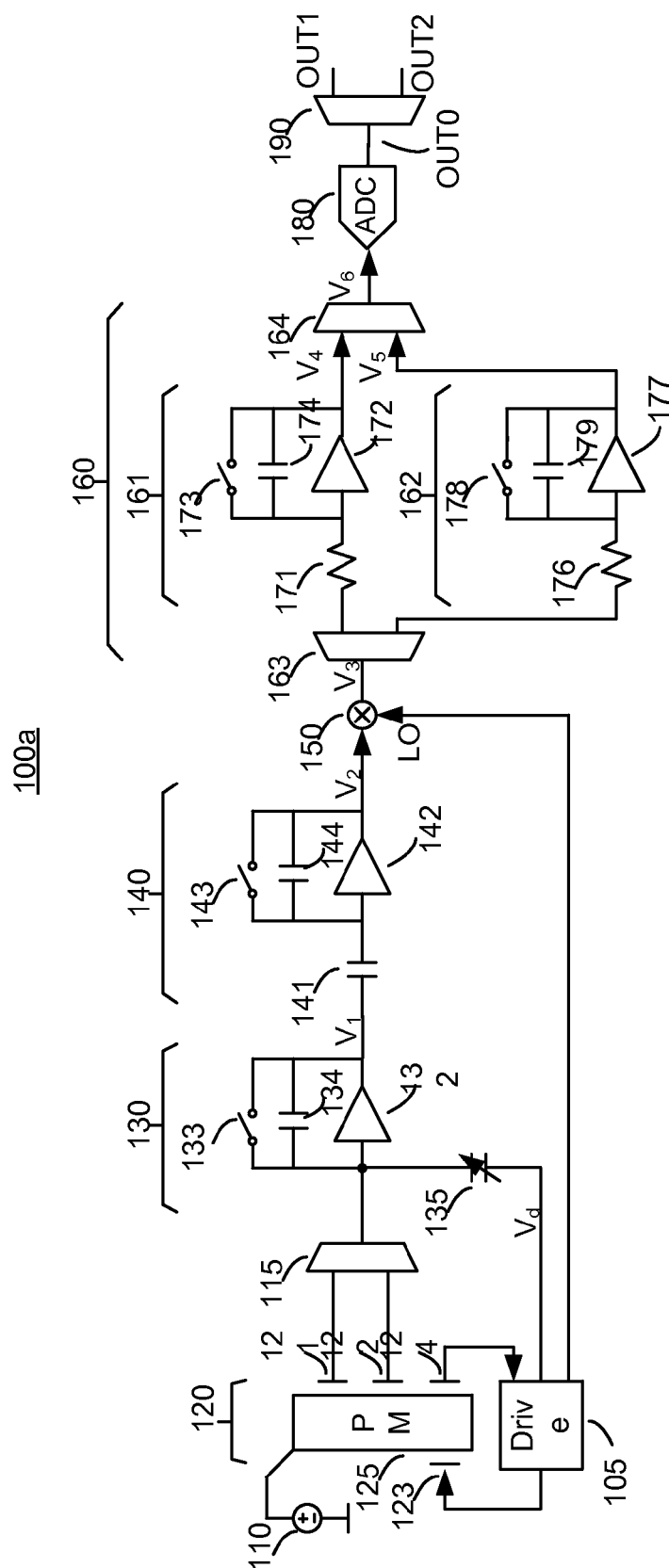


Figure 1a

100b

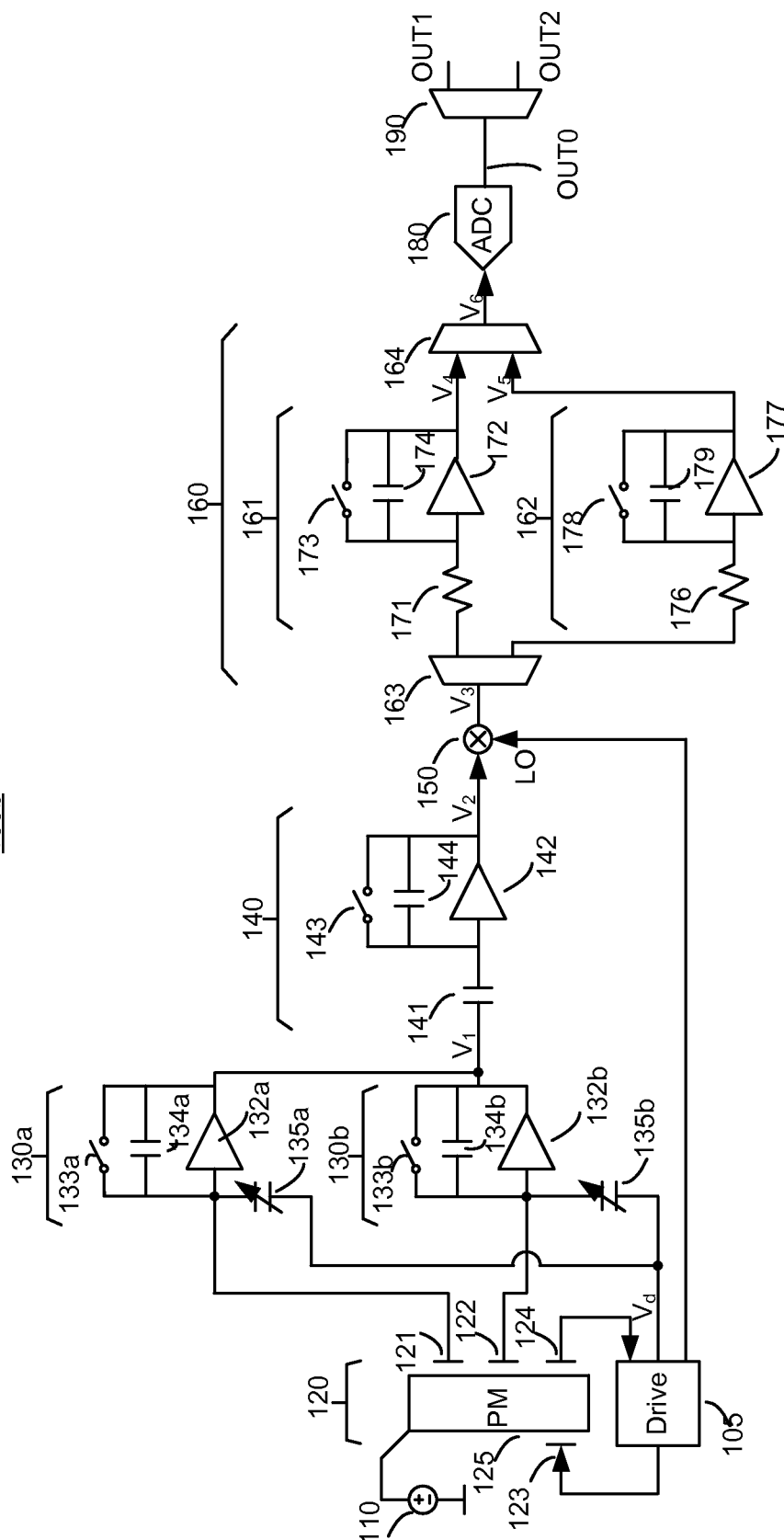


Figure 1b

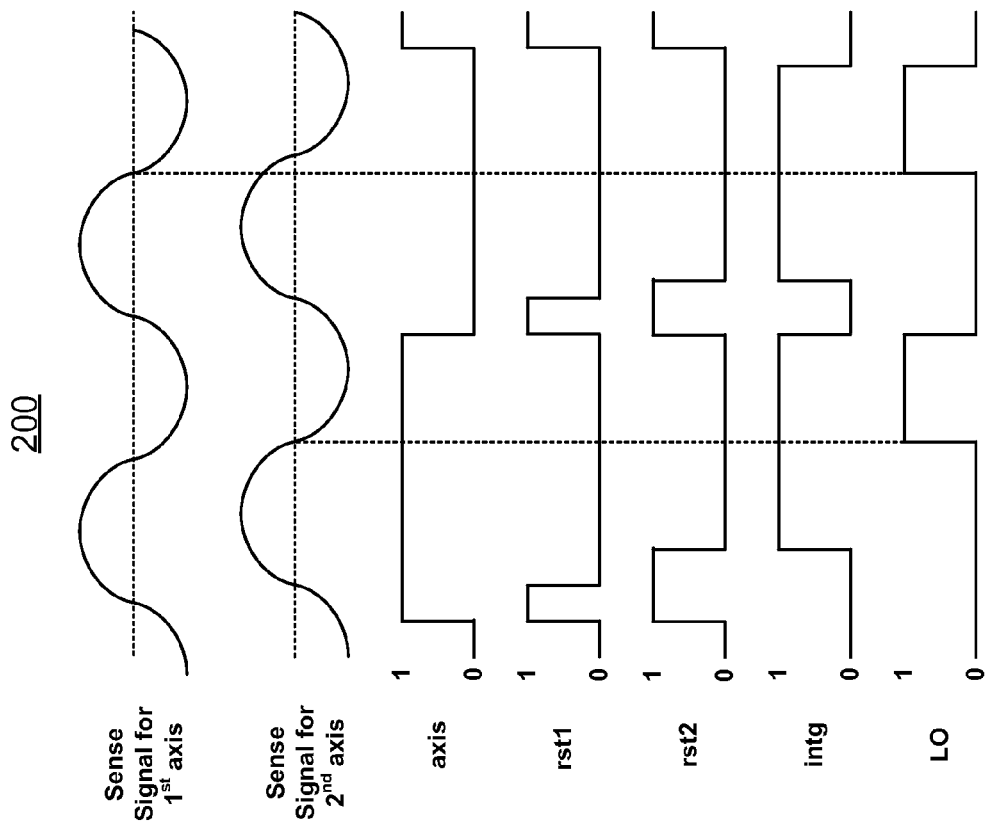


Figure 2

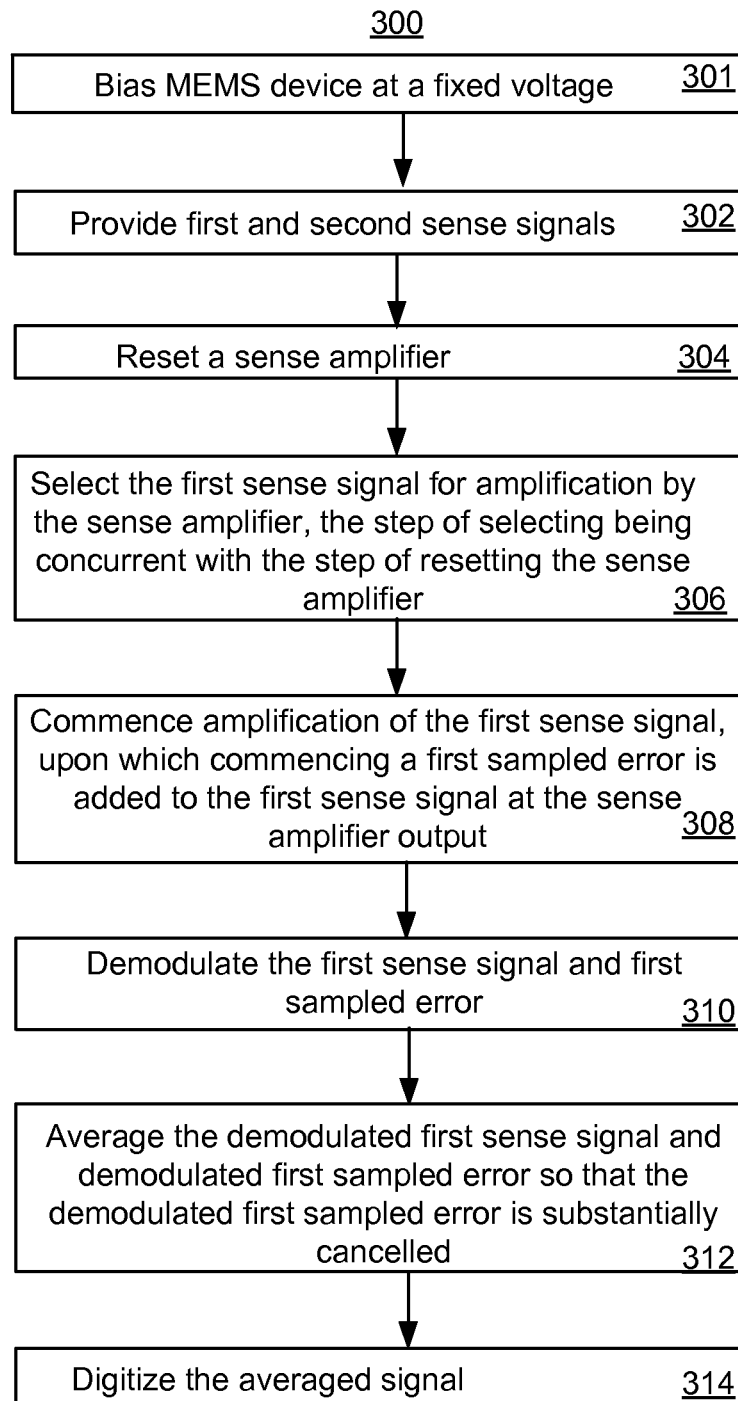
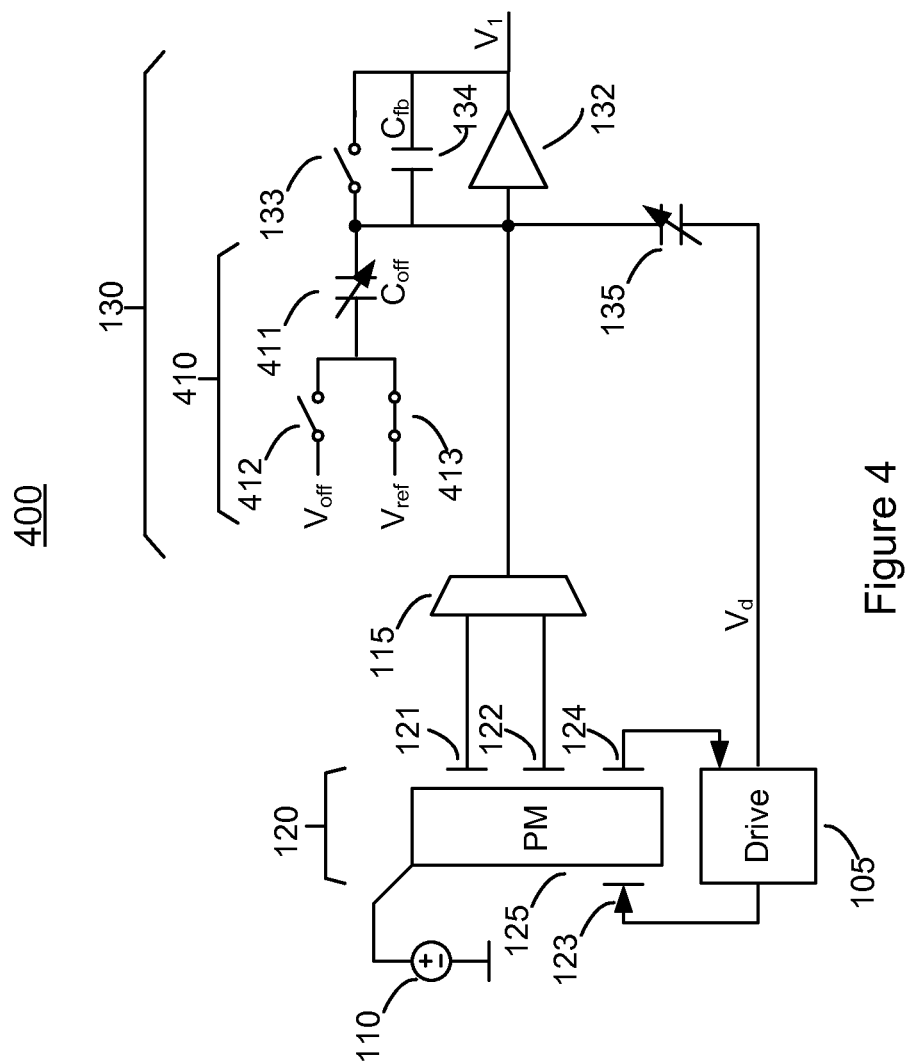


Figure 3



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ROUND-ROBIN SENSING DEVICE AND METHOD OF USE

CROSS-REFERENCE TO RELATED APPLICATION

This application claims benefit under 35 USC 119(e) of U.S. Provisional Patent Application No. 61/780,371, filed on Mar. 13, 2013, entitled "ROUND-ROBIN GYROSCOPE," which is incorporated herein by reference in its entirety.

FIELD OF THE INVENTION

The present invention relates generally to sensors and more particularly to sensing of multi-axis sensors.

BACKGROUND

MEMS sensing devices such as multi-axis gyroscope are utilized in a variety of applications. Normally each sensing axis has its own sensing circuit, meaning three copies of the same sensing circuit might be required for a three-axis sensor. This is particularly true of continuous-time sensing. The duplication of the sensing circuit leads to higher costs and sizes of the devices and there is a desire to reduce them by sharing the sensing circuit. The present invention addresses such a need.

SUMMARY

A round-robin sensing device is disclosed. The round-robin sensing device comprises a MEMS device, wherein the MEMS device includes first and second sense electrodes. The round-robin sensing device also comprises a multiplexer coupled to the first and second sense electrodes, at least one sense amplifier coupled to the multiplexer, a demodulator coupled to the at least one sense amplifier, and an integrate and dump circuit coupled to the demodulator. Finally, the round-robin sensing device comprises an analog-to-digital converter (ADC) coupled to the de-multiplexer, wherein the multiplexer, the at least one sense amplifier and the demodulator provide a continuous time sense path during amplification that is resettable and wherein the integrate and dump circuit and the ADC provide a discrete time processing path when switching between the first and second sense electrodes.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1a is a block diagram of a first embodiment of a round-robin multi-axis gyroscope.

FIG. 1b is a block diagram of a second embodiment of a round-robin multi-axis gyroscope.

FIG. 2 shows an embodiment of the timing diagram for the control signals of the round-robin gyroscope.

FIG. 3 is a flow chart of a method of operation of the round-robin gyroscope in accordance with an embodiment.

FIG. 4 shows an embodiment of a part of the round-robin gyroscope sense path including a MEMS device, a drive system, and a first sense amplifier with an offset cancellation circuit.

DETAILED DESCRIPTION

The present invention relates generally to sensors and more particularly to round-robin sensing devices. The following description is presented to enable one of ordinary

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skill in the art to make and use the invention and is provided in the context of a patent application and its requirements. Various modifications to the preferred embodiments and the generic principles and features described herein will be readily apparent to those skilled in the art. Thus, the present invention is not intended to be limited to the embodiments shown, but is to be accorded the widest scope consistent with the principles and features described herein.

In the described embodiment, round-robin method refers to the method where each axis of the gyroscope is sensed for a certain period of time. Round-robin multi-axis gyroscope refers to the gyroscope with multi-axis sensing and one sensing circuit, where each of the axes of the gyroscope is read out by the sensing circuit one at a time. By applying a round-robin method to a sensing device such as a three axis gyroscope the number of sense path components can be substantially reduced. In so doing, the overall chip size and cost is substantially reduced. To describe the features of the present invention in more detail refer now to the following description in conjunction with the accompanying figures.

FIG. 1a is the block diagram of a first embodiment of round-robin multi-axis gyroscope 100a comprising a sensing device and sensing circuit operating with a continuous-time sensing framework. Although a gyroscope is described herein one of ordinary skill in the art readily recognizes that round-robin sensing device could be a variety of sensing devices. The round-robin multi-axis gyroscope 100a includes a DC voltage source 110, a gyroscope MEMS device 120, a drive system 105, a multiplexer 115, a first sense amplifier 130, a second sense amplifier 140, a mixer 150, an integrate and dump circuit 160, an analog-to-digital converter (ADC) 180, and a de-multiplexer 190. The gyroscope MEMS device 120 includes a proof mass 125, a MEMS sense electrode for the first axis 121, a MEMS sense electrode for the second axis 122, a MEMS drive electrode 123, and a MEMS drive-sense electrode 124.

The first sense amplifier 130 includes an operational amplifier 132, a reset switch 133, a feedback capacitor 134, and a feed-through capacitor 135 for quadrature cancellation. The second sense amplifier 140 includes an input capacitor 141, an operational amplifier 142, a reset switch 143, and a feedback capacitor 144. The integrate and dump circuit 160 includes an input de-multiplexer 163, an output multiplexer 164, two integrators 161 and 162, and each of them includes a resistor 171/176, a reset switch 173/178, a feedback capacitor 174/179, and an operational amplifier 172/177.

MEMS proof mass 125 is biased at a high voltage by DC voltage source 110. The drive system 105 receives input from MEMS drive-sense electrode 124 and drives gyroscope MEMS device 120 to oscillation at drive frequency through drive electrode 123. Drive signal Vd from drive 105 feeds first sense amplifier 130 for quadrature cancellation through feed-through capacitor 135. A clock signal LO is generated and sent to mixer 150 for sense signal demodulation.

Round-robin multi-axis gyroscope 100a has two sensing periods. During the first sensing period, multiplexer 115 is configured to pick up the sense signal for the first axis and quadrature signal from sense electrode 121; during the second sensing period, multiplexer 115 is configured to pick up the sense signal for the second axis and quadrature signal from sense electrode 122. The sense signals are amplitude modulated signals with carrier frequency equal to drive frequency. Quadrature signal is a sinusoidal signal with substantially fixed amplitude running at drive frequency. The phase of quadrature signal is in quadrature relationship with that of the sense signals. Quadrature signal is mostly

cancelled by the drive signal V_d through the feed-through capacitor **135**, and what remains is called residual quadrature signal. The amplitude of quadrature signal may vary from axis to axis, and feed-through capacitor **135** may be configured differently during each sensing period for maximum quadrature cancellation. The sense signal and residual quadrature signal pass through first and second sense amplifiers **130** and **140** and are demodulated by mixer **150**. Clock signal LO runs at drive frequency and is substantially in-phase with the sense signal to maximize the gain of mixer **150** for the sense signal, and residual quadrature is substantially removed given its phase relationship to the sense signal and LO. The output of mixer **150** is processed by integrate and dump circuit **160** and converted to digital signal by ADC **180**. The ADC output OUT0 then passes through a de-multiplexer **190**. The sense signal for the first axis is de-multiplexed to OUT1 and the second axis is de-multiplexed to OUT2.

FIG. 2 shows an embodiment of a timing diagram for the control signals of the round-robin multi-axis gyroscope. The operating period for each axis is one period of the sense signal. As drawn, quadrature signal is neglected. When signal axis is set to 0, the first axis is selected and sense electrode **121** is connected to first sense amplifier **130** through multiplexer **115**; when signal axis is set to 1, the second axis is selected and sense electrode **122** is connected to the first sense amplifier **130** through multiplexer **115**. When signal rst1 is 1, reset switch **133** is enabled to reset first sense amplifier **130**. When signal rst2 is 1, reset switch **143** is enabled to reset second sense amplifier **140**. Second sense amplifier **140** is kept in reset for some duration after first sense amplifier **130** comes out of reset, and by this way the sampled offset and noise from first sense amplifier **130** when it comes out of reset is absorbed by input capacitor **141** of the second sense amplifier and will not propagate to the output.

When signal axis is set to 0, de-multiplexer **163** is configured to pass input signal V_3 to first integrator **161**. Reset switch **173** is enabled when signal intg is set to 0 and disabled when signal intg is set to 1, and input signal V_3 will be integrated onto feedback capacitor **174**. Signal LO transitions from 0 to 1 substantially at the zero crossing of the sense signal for the first axis, and the transition also aligns substantially to the middle of the integration period. By doing so, (a) frequency components near DC which includes the sampled offset and noise from the first and second sense amplifiers **130/140** when the second sense amplifier comes out of reset, (b) frequency components near even harmonics of the drive frequency, and (c) residual quadrature signal, are averaged and nullified by the first integrator **161**. Multiplexer **164** is configured to pass output signal V_5 from second integrator **162** to the ADC. Reset switch **178** is disabled over the whole period so that second integrator **162** holds the integrated value from the previous period. De-multiplexer **190** is configured to pass ADC output OUT0 to OUT2.

When signal axis is set to 1, de-multiplexer **163** is configured to pass input signal V_3 to second integrator **162**. Reset switch **178** is enabled when signal intg is set to 0 and disabled when signal intg is set to 1, and input signal V_3 will be integrated onto the feedback capacitor **179**. Signal LO transitions from 0 to 1 substantially at the zero crossing of the sense signal for the first axis, and the transition also aligns substantially to the middle of the integration period. By doing so, (a) frequency components near DC which includes the sampled offset and noise from the first and second sense amplifiers **130/140** when the second sense

amplifier comes out of reset, (b) frequency components near even harmonics of the drive frequency, and (c) residual quadrature signal, are averaged and nullified by first integrator **162**. Multiplexer **164** is configured to pass output signal V_4 from first integrator **161** to the ADC. Reset switch **173** is disabled over the whole period to hold the integrated value from the previous period. De-multiplexer **190** is configured to pass ADC output OUT0 to OUT1.

The control signals keep repeating and the sense signals from the first and second axes are processed in a round-robin fashion. The integration window dictated by signal intg and signal LO may shift in time from axis to axis for individual phase alignment. Although the integration window for each axis is less than the period of processing the signal for each axis and may shift in time, integrate and dump circuit **161** does hold the value for the whole period after each integration process. This enables the ADC to have a consistent sampling operation going from axis to axis.

Although FIG. 2 indicates that the operating period of each axis is one period of the sense signal, one can extend the idea and instead do half a period of the sense signal, two periods of the sense signal, etc.

Although the embodiments describe 2-axis operation, other embodiments can provide 3-axis operation or more without departing from the scope and spirit as set forth.

Although the embodiments describe MEMS signal multiplexing by using multiplexer **115**, signal multiplexing can be achieved in different ways without departing from the scope and spirit as set forth. FIG. 1b shows an embodiment where first sense amplifier **130** is duplicated so that multiplexer **115** is not necessary. Sense amplifier **130a** connects to MEMS electrode **121** and sense amplifier **130b** connected to electrode **122**. The outputs of the sense amplifiers are then multiplexed at V_1 by turning only one first sense amplifier on at a time. This embodiment may be advantageous by reducing the number and size of switches at the amplifier inputs.

The second sense amplifier **140** is optional. If it is removed, the sampled offset and noise from the first sense amplifier **130** will still be nullified by the mixer.

Although the embodiments describe the integrate and dump circuit **160** having two separate input resistors **171/176** after de-multiplexer **163**, one may instead have one resistor before the de-multiplexer **163** while still maintaining the same functionality.

The round-robin gyroscope can be easily operated as a 1-axis gyroscope when multiplexer **115** is configured to only pick up signal from MEMS electrode **121** or **122** to first amplifier **130** and de-multiplexer **190** is configured to pass signal OUT0 only to OUT1 or OUT2.

FIG. 3 shows a flow chart of a method of operation of the round-robin gyroscope in accordance with an embodiment. As is seen, a MEMS device is biased at a fixed voltage via step **301**. First and second sense signals are provided via step **302**. With reference to FIG. 1a, the first sense signal may refer to sense signal from first axis through MEMS electrode **121** and the second sense signal may refer to the sense signal from second axis through MEMS electrode **122**. Then a sense amplifier is reset, via step **304**. Thereafter, the first sense signal for amplification is selected by first sense amplifier, via step **306**. The selecting is concurrent with resetting the sense amplifier.

Thereafter, amplification of the first sense signal is provided, via step **308**, upon which commencing a first sampled error is added to the first sense signal at the sense amplifier output. The first sampled error is contributed by the instantaneous first sense signal, quadrature signal, harmonic sig-

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nals, MEMS noise, and circuit noise. Then the first sense signal and first sampled error are demodulated, via step 310. The demodulated first sense signal and demodulated first sampled error are averaged so that the demodulated first sampled error is substantially cancelled, via step 312. The averaged signal is digitized, via step 314.

FIG. 4 shows an alternative embodiment of the round-robin gyroscope sense path including the MEMS 120, drive system 105, and the first sense amplifier 130 with an offset cancellation circuit 410. One problem for the first sense amplifier 130 during round-robin operation is that whenever reset switch 133 is opened, an offset can be sampled at the output V1 if the instantaneous input signal to amplifier 130 is not zero. Depending on the timing when reset switch 133 is opened, any of or any combination of sense signal, quadrature signal, and harmonics of the sense/quadrature signals may be sampled.

The sampled offset can potentially cause two issues: (a) if the rate of reset is not aligned properly to the frequencies of the input signals, the sampled offset could change in time and generate a tone that degrades the signal-to-noise ratio; (b) the sampled offset consumes signal headroom and thereby limits the maximum measurable sense signal.

Regarding issue (a), it is handled by making the reset rate synchronous to the input signal, i.e. reset rate is at drive frequency or sub-harmonic of the drive frequency. In so doing the sampled offset is fixed over time.

Regarding issue (b), it is handled by offset cancellation circuit 410. When amplifier 130 is in reset phase (reset switch 133 is closed), the voltage gain of the amplifier is very small and output voltage V1 is close to reference voltage Vref. Switch 412 is turned on at this time and a voltage (Voff-Vref) appears across trim capacitor 411 with total charge of Coff (Voff-Vref). At the moment reset switch 133 is opened, switch 412 is turned off and switch 413 turned on.

Vref driving trim capacitor 411 causes the charge on trim capacitor 411 to transfer to amplifier feedback capacitor 134, leading to a DC voltage offset at output V1 equal to $-C_{off}(V_{off}-V_{ref})/C_{fb}$. If the value of Voff and Coff are chosen properly, the DC offset can cancel the sampled offset due to a finite input signal at the moment the amplifier comes out of reset, thereby recovering the loss on signal headroom. Although voltages Voff and Vref are being used in offset cancellation circuit 410 as described above, other implementations are possible, e.g. using Voff1 and Voff2.

Although offset cancellation circuit 410 described above is for single-ended amplifiers, the technique can be easily extended to differential amplifiers by adopting two sets of offset cancellation network: one for the positive, and the other for the negative side of the amplifier. Two bias voltages, e.g. Voff1 and Voff2, can be used to charge trim capacitors to positive and negative voltages. The offset cancellation polarity inversion can be achieved by dumping the charge on the trim capacitor to the opposite side of the amplifier, and Voff1/Voff2 can be of fixed values.

Note that Voff, Voff1 and Voff2 can be either static voltages or periodic voltage signals as long as their values are consistent every time the reset switch is opened. Based on this argument, Voff, Voff1, and Voff2 can be tied to the drive signal Vd or its differential version Vd1 and Vd2 directly given their frequency is the same as the amplifier reset rate, and the moment the reset switch is opened is close to the peak of the drive signal Vd/Vd1/Vd2. By implementing this way, a voltage buffer for providing Voff or voltage buffers for Voff1 and Voff2 can be eliminated.

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The described embodiments merge two (for 2-axis operation) or three (for 3-axis operation) sense paths into a single sense path which in turn reduces the circuit area and lowers the power consumption when compared to traditional continuous-time sensing gyroscope architectures.

Compared to a traditional discrete-time gyroscope sensing architecture, this method pertains to the continuous-time circuit scheme and provides (a) a smaller noise bandwidth; (b) compatibility with the use of fixed high-voltage proof-mass biasing to enable larger sense signal; (c) simpler quadrature cancellation scheme as implemented by a feed-through capacitor. For the same power consumption, the described embodiments have better noise performance over discrete-time gyroscope, or for the same noise performance, lower power consumption.

Although the present invention has been described in accordance with the embodiments shown, one of ordinary skill in the art will readily recognize that there could be variations to the embodiments and those variations would be within the spirit and scope of the present invention. Accordingly, many modifications may be made by one of ordinary skill in the art without departing from the spirit and scope of the present invention.

What is claimed is:

1. A round-robin sensing device comprising:

a MEMS device; wherein the MEMS device includes first and second sense electrodes;

a multiplexer coupled to the first and second sense electrodes;

at least one sense amplifier coupled to the multiplexer;

a demodulator coupled to the at least one sense amplifier;

an integrate and dump circuit coupled to the demodulator; and

an analog-to-digital converter (ADC) coupled to a demultiplexer; wherein the multiplexer, the at least one sense amplifier and the demodulator provide a continuous time sense path during amplification that is resettable and wherein the integrate and dump circuit and the ADC provide a discrete time processing path when switching between the first and second sense electrodes.

2. The round-robin sensing device of claim 1, wherein the first sense electrode senses in a first axis and the second electrode senses in a second axis.

3. The round-robin sensing device of claim 1, wherein the round-robin sensing device comprises a multi-axis gyroscope.

4. The round-robin sensing device of claim 3, further comprising a drive system for driving the MEMS device.

5. The round-robin sensing device of claim 4, further comprising a feed-through capacitor coupled to drive system and the at least one sense amplifier.

6. The round-robin sensing device of claim 1, wherein the at least one sense amplifier comprises first and second sense amplifiers.

7. The round-robin sensing device of claim 6, wherein the first sense amplifier includes a first operational amplifier coupled to the multiplexer, a first reset switch and a first feedback capacitor coupled in feedback relationship to the first operational amplifier.

8. The round-robin sensing device of claim 6, wherein the second sense amplifier includes an input capacitor coupled to the first sense amplifier, a second operational amplifier coupled to the input capacitor, a second reset switch and a second feedback capacitor coupled in feedback relationship with the second operational amplifier.

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9. The round-robin sensing device of claim 1, wherein the integrate and dump circuit comprises:

- an input de-multiplexer;
- a first and a second integrator coupled to the input de-multiplexer; and
- a multiplexer coupled to an output of the first and second integrators.

10. The round-robin sensing device of claim 9, wherein each of the first and second integrators comprises:

- a resistor coupled to the input de-multiplexer;
- an operational amplifier coupled to the resistor;
- a reset switch coupled in feedback relationship with the operational amplifier; and
- a capacitor coupled in feedback relationship with the operational amplifier.

11. The round-robin sensing device of claim 9, wherein the input de-multiplexer includes a resistor and each of the first and second integrators comprises:

- an operational amplifier coupled to the input de-multiplexer;
- a reset switch coupled in feedback relationship with the operational amplifier; and
- a capacitor coupled in feedback relationship with the operational amplifier.

12. A round-robin sensing device comprising:

- a MEMS device; wherein the MEMS device includes first and second sense electrodes;
- a plurality of sense amplifiers adapted to be selectively coupled to the first and second sense electrodes;
- a demodulator coupled to the plurality of sense amplifiers;
- an integrate and dump circuit coupled to the demodulator; and
- an analog-to-digital converter (ADC) coupled to a de-multiplexer; wherein the de-multiplexer, the plurality of sense amplifiers and the demodulator provide a continuous time sense path during amplification that is resettable and wherein the integrate and dump circuit and the ADC provide a discrete time processing path when switching between the first and second sense electrodes.

13. The round-robin sensing device of claim 12, wherein the first sense electrode senses in a first axis and the second electrode senses in a second axis.

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14. The round-robin sensing device of claim 12, wherein the plurality of sense amplifiers comprises first and second sensor amplifiers.

15. The round-robin sensing device of claim 12, wherein each of the plurality of sense amplifiers includes a first operational amplifier coupled to one of the first and second sense electrodes, a reset switch and a first feedback capacitor coupled in feedback relationship to the first operational amplifier.

16. The round-robin sensing device of claim 12, wherein the round-robin sensing device comprises a multi-axis gyroscope.

17. The round-robin sensing device of claim 16, further comprising a drive system for driving the MEMS device.

18. The round-robin sensing device of claim 17, further comprising a feed-through capacitor coupled to drive system and the at least one sense amplifier.

19. The round-robin sensing device of claim 12, wherein the integrate and dump circuit comprises:

- an input de-multiplexer;
- first and second integrators coupled to the input de-multiplexer; and
- a multiplexer coupled to an output of the first and second integrators.

20. The round-robin sensing device of claim 19, wherein each of the first and second integrators comprises:

- a resistor coupled to the input de-multiplexer;
- an operational amplifier coupled to the resistor;
- a reset switch coupled in feedback relationship with the operational amplifier; and
- a capacitor coupled in feedback relationship with the operational amplifier.

21. The round-robin sensing device of claim 19, wherein the input de-multiplexer includes a resistor and each of the first and second integrators comprises:

- an operational amplifier coupled to the input de-multiplexer;
- a reset switch coupled in feedback relationship with the operational amplifier; and
- a capacitor coupled in feedback relationship with the operational amplifier.

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